

## **AMENDMENTS TO THE CLAIMS**

The following listing of claims will replace all prior versions and listings of claims in the application.

### **LISTING OF CLAIMS**

1. (currently amended) An image processing apparatus comprising:  
an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image ~~viewed from a virtual point of view from these camera images~~ using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein the image processing part changes at least one selected from a position, a direction of a line of sight, and a focal length of the virtual point of view in accordance with a running state of the vehicle.

2. (original) The image processing apparatus of claim 1,  
wherein the image processing part changes at least one selected from a position, a direction of a line of sight, and a focal length of the virtual point of view in accordance with a running speed of the vehicle.

3. (original) The image processing apparatus of claim 1,

wherein the image processing part changes at least one selected from a position, a direction of a line of sight, and a focal length of the virtual point of view, and controls capturing of an image outside a view range of the changed virtual point of view.

4. (original) The image processing apparatus of claim 3,  
wherein the image processing part controls the capturing of an image outside a view range of the changed virtual point of view by changing a model for image synthesis.

5. (original) The image processing apparatus of claim 1  
wherein the image processing part changes at least one selected from a position, a direction of a line of sight, and a focal length of the virtual point of view in accordance with a steering angle of the vehicle.

6. (currently amended) The image processing apparatus of claim 1,  
wherein the vehicle includes an object detecting sensor ~~for detecting operable to~~  
detect an obstacle, and  
the image processing part changes at least one of selected from a position, a direction of a line of sight, and a focal length of the virtual point of view in accordance with results of detection by the object detecting sensor.

7. (original) The image processing apparatus of claim 1,

wherein the image processing part includes an original mapping table and generates a synthetic image using a mapping table that is cut out from the original mapping table, and

the image processing part changes at least one selected from a position, a direction of a line of sight, and a focal length of the virtual point of view by changing the mapping table to be cut out from the original mapping table.

8. (currently amended) An image processing apparatus comprising:

an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image viewed from a virtual point of view from these camera images using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein the image processing part controls capturing of an image outside a view range of the virtual point of view in accordance with a running state of the vehicle.

9. (currently amended) A monitoring system comprising:

a plurality of cameras ~~shooting~~ operable to shoot surroundings of a vehicle;

an image processing part ~~for receiving~~ operable to receive images captured by the plurality of cameras and operable to generate a synthetic image viewed from a virtual point of view from these camera images using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view; and

a display part ~~for displaying~~ operable to display the synthetic image,  
wherein the image processing part changes at least one selected from a position,  
a direction of a line of sight, and a focal length of the virtual point of view in accordance  
with a running state of the vehicle.

10. (currently amended) An image processing apparatus comprising:  
an image processing part ~~for receiving~~ operable to receive images captured by a  
plurality of cameras shooting surroundings of a vehicle and operable to generate a  
synthetic image ~~from these camera images~~ using the received images captured by the  
plurality of cameras,

wherein the image processing part generates an image including a first image  
and a second image as the synthetic image,

the first image ~~being viewed from the~~ showing the vehicle from a virtual point of  
view,

the second image being viewed from a viewpoint that is different from the virtual  
point of view of the first image in at least one selected from a position, a direction of a  
line of sight and a focal length, or

the second image being different from the first image in a model.

11. (original) The image processing apparatus of claim 10,  
wherein the second image is at least one of the camera images.

12. (original) The image processing apparatus of claim 10,

wherein the first image is a close view image showing the vehicle and surroundings thereof, and

the second image is a distant view image showing an area distant from the surrounding area of the vehicle that is shown by the close view image.

13. (original) The image processing apparatus of claim 12, wherein the image processing part arranges the distant view image around the close view image in the synthetic image.

14. (original) The image processing apparatus of claim 13, wherein the distant view image is an image having continuity with the close view image.

15. (original) The image processing apparatus of claim 10, wherein the first image shows at least a part of the vehicle and at least a part of the surroundings of the vehicle, and the second image is obtained by enlarging at least a part of the region shown by the first image.

16. (currently amended) A monitoring system comprising:  
a plurality of cameras ~~shooting~~ operable to shoot surroundings of a vehicle;

an image processing part ~~for receiving~~ operable to receive images captured by the plurality of cameras to generate a synthetic image ~~from these camera images~~ using the received images captured by the plurality of cameras; and

a display part ~~for displaying~~ operable to display the synthetic image,

wherein the image processing part generates an image including a first image and a second image as the synthetic image,

the first image ~~being viewed~~ showing the vehicle from a virtual point of view,

the second image being viewed from a viewpoint that is different from the virtual point of view of the first image in at least one selected from a position, a direction of a line of sight and a focal length, or

the second image being different from the first image in a model.

17. (currently amended) An image processing apparatus comprising:

an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image from these camera images using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein in the synthetic image, the image processing part displays at least a part of a vehicle region where the vehicle is present, and an attention drawing region for drawing attention in which at least a part of the surroundings of the vehicle is shown and which corresponds to at least a part of a blind spot region around the vehicle that is not shot by any of the cameras.

18. (currently amended) The image processing apparatus of claim 17,  
~~wherein the synthetic image is an image viewed from a virtual point of view that~~  
~~is set above the vehicle~~ the virtual point of view is set above the vehicle.

19. (original) The image processing apparatus of claim 17,  
wherein the image processing part displays an illustration image or an actual  
image of the vehicle on the vehicle region.

20-21. (cancelled)

22. (previously presented) The image processing apparatus of claim 17,  
wherein the image processing part determines a range of a region obtained by  
combining the blind spot region and the vehicle region, using region data showing a  
projection region of the vehicle in each camera image.

23. (currently amended) A monitoring system comprising:  
a plurality of cameras ~~shooting~~ operable to shoot surroundings of a vehicle;  
an image processing part ~~for receiving~~ operable to receive images captured by  
the plurality of cameras and operable to generate a synthetic image from these camera  
images using the received images captured by the plurality of cameras, the synthetic  
image showing the vehicle from a virtual point of view; and  
a display part ~~for displaying~~ operable to display the synthetic image,

wherein in the synthetic image, the image processing part displays at least a part of a vehicle region where the vehicle is present, and an attention drawing region for drawing attention in which at least a part of the surroundings of the vehicle is shown and which corresponds to at least a part of a blind spot region around the vehicle that is not shot by any of the cameras.

24. (currently amended) An image processing apparatus comprising:

an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image from these camera images using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein the image processing part generates the synthetic image, using a mapping table including first mapping data describing a ~~correspondence~~ relationship between pixels of the synthetic image and pixels of the camera images, and second mapping data describing an identifier showing that a pixel of the synthetic image corresponds to pixel data other than the camera images, and

~~and~~ wherein the pixel data other than the camera images show the vehicle or a blind spot region that is present in at least a part of the surroundings of the vehicle.

25. (cancelled)

26. (original) The image processing apparatus of claim 24,



wherein the image processing part stores a predetermined image other than the camera images, and

with respect to the pixel of the synthetic image, the second mapping data describe coordinate values corresponding to the pixel in the stored predetermined image.

27. (original) The image processing apparatus of claim 24,  
wherein the second mapping data describe pixel data corresponding to the pixel of the synthetic image.

28. (currently amended) An image processing apparatus comprising:  
an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image ~~from these camera images~~ using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein the image processing part uses mapping data describing a ~~correspondence~~ relationship between pixels of the synthetic image and a plurality of pixel data including one or both of pixel data of the camera images and pixel data other than the camera images, and describing a rate of necessity with respect to each of the pixel data, and weights each pixel data in accordance with the rate of necessity,  
thereby generating the pixel data of the pixels of the synthetic image.

29. (currently amended) An image processing apparatus comprising:

an image processing part ~~for receiving~~ operable to receive images captured by a plurality of cameras shooting surroundings of a vehicle and operable to generate a synthetic image ~~from these camera images~~ using the received images captured by the plurality of cameras, the synthetic image showing the vehicle from a virtual point of view,

wherein the image processing part includes an original mapping table, cuts out a mapping table describing a correspondence relationship between pixels of the synthetic image and pixels of the camera images, and generates the synthetic image, using the cut-out mapping table.

30. (previously presented) The image processing apparatus of claim 10 wherein the virtual point of view has been viewpoint-converted from an actual viewpoint.

31. (previously presented) The monitoring system of claim 16 wherein the virtual point of view has been viewpoint-converted from an actual viewpoint.

32. (new) The image processing apparatus of claim 1, wherein the virtual point of view is set outside of the vehicle.

33. (new) The image processing apparatus of claim 1, wherein the virtual point of view is set above the vehicle.

34. (new) The image processing apparatus of claim 17, wherein the virtual point of view is set outside of the vehicle.